Refine Search

Your wildcard search against 10000 terms has yielded the results below.
Your result set for the last L# is incomplete.
The probable cause is use of unlimited truncation. Revise your search strategy to use limited truncation.

Search Results -

Terms	Documents
L39 and (compar$ same (colinear$ or regressi$) same error$)	0

Database:
US Pre-Grant Publication Full-Text Database
US Patents Full-Text Database
US OCR Full-Text Database
EPO Abstracts Database
JPO Abstracts Database
Derwent World Patents Index
IBM Technical Disclosure Bulletins

Search: 10/605768

Refine Search | Recall Text | Clear | Interrupt

Search History

DATE: Saturday, August 18, 2007 Purge Queries Printable Copy
Create Case

Set Name side by side	Query	Hit Count	Set Name result set
	DB=PGPB,USPT,USOC,EPAB,JPAB,DWPI,TDBD; THES=ASSIGNEE; PLUR=YES; OP=OR		
	L39 and (compar$ same (colinear$ or regressi$) same		

L52	error$)	0	L52
L51	L39 and (compar$ same (colinear$ or regressi$) same (threshold$ with error$))	0	L51
L50	L39 and (compar$ same confiden$ same (threshold$ with error$))	0	L50
L49	L39 and (compar$ same (confiden$) same (threshold$ with error$))	0	L49
L48	L39 and gps$ and vehicle and (compar$ same (confiden$) same (threshold$ with error$))	0	L48
L47	L39 and gps$ and vehicle and (compar$ same (colinear$ or regressi$) same (threshold$ with error$))	0	L47
L46	L41 and gps$ and vehicle and (compar$ same (colinear$ or regressi$) same (threshold$ with error$))	0	L46
L45	L44 and gps$ and vehicle and (compar$ same (colinear$ or regressi$) same (threshold$ with error$))	0	L45
	DB=USPT; THES=ASSIGNEE; PLUR=YES; OP=OR		
L44	L43 and (compar$ same (driver$ near4 input$))	10	L44
	DB=PGPB,USPT,USOC,EPAB,JPAB,DWPI,TDBD; THES=ASSIGNEE; PLUR=YES; OP=OR		
L43	L42 and inputs	26	L43
L42	L41 and (driver$ near4 input$)	26	L42
L41	L40 and ((automobile or vehicle or car$ or driv$) same input$)	97	L41
L40	L39 and ((701/201 |701/202 |701/208 |701/209 |701/210 |701/211 |701/213).ccls.)	150	L40
L39	L37 or L38	530	L39
L38	((compar$ with (path$ or way$ or route$)) same gps$) and @pd<=20031024	306	L38
L37	((compar$ with (path$ or way$ or route$)) same gps$) and @ad<=20031024	521	L37
	DB=PGPB,USPT,USOC; THES=ASSIGNEE; PLUR=YES; OP=OR		

L36	L35 and @ad<=20031024	26	L36
L35	L34 and ((compar$ with (path$ or way or route)) with (predict$ or forecast$)) and ((calculat$ or desire$ or plan$) with (path$ or way or route))	41	L35
L34	(701/202 |701/208 |701/209 |701/210 |701/213).ccls.	5214	L34

DB=PGPB,USPT,USOC,EPAB,JPAB,DWPI,TDBD; THES=ASSIGNEE; PLUR=YES; OP=OR

L33	L32 and ((calculat$ or desire$ or plan$) with (path$ or way or route))	21	L33
L32	L30 and ((compar$ with (path$ or way or route)) with (predict$ or forecast$))	34	L32
L31	L30 and (compar$ with (predict$ or forecast$))	36	L31
L30	L16 and ((701/201 |701/202 |701/208 |701/209 |701/210 |701/211 |701/213).ccls.)	44	L30
L29	L28 and ((701/201 |701/202 |701/208 |701/209 |701/210 |701/211 |701/213).ccls.)	1	L29
L28	L24 or L25	45	L28
L27	L26	9	L27
L26	L25	9	L26
L25	(linear$ with regression$) and (pitch$ and yaw$ and (speed$ or velocit$)) and L11	9	L25
L24	(linear$ with regression$) and (pitch$ and yaw$ and (speed$ or velocit$)) and gps$	45	L24
L23	(linear$ with regression$) and (pitch$ and yaw$ and (speed$ or velocit$)) and L16	1	L23
L22	(linear$ adj regression$) and (pitch$ and yaw$ and (speed$ or velocit$)) and L16	1	L22
L21	(linear$ adj regression$ adj model$) and (pitch$ and yaw$ and (speed$ or velocit$)) and L16	1	L21
L20	L19 and (pitch$ or yaw$ or (speed$ or velocit$))	2	L20
L19	L16 and (linear$ adj regression$ adj model$)	2	L19
L18	L17 and ((speed$ or velocit$) with (vehicle or car$ or automobil$))	7	L18
L17	L16 and ((confide$ or trust$ or reliab$) near2	16	L17

	(degree$ or level$ or scal$))		
L16	L14 or L15	189	L16
L15	L13 and @pd<=20031024	122	L15
L14	L13 and @ad<=20031024	189	L14
L13	gps$ and ((compar$ with (path$ or way or route)) same (predict$ or forecast$))	287	L13
L12	L10 and @pd<=20031024	5820	L12
L11	L10 and @ad<=20031024	9464	L11
L10	gps$ and ((compar$ with (path$ or way or route)) sme (predict$ or forecast$))	15325	L10
DB=EPAB,JPAB,DWPI,TDBD; THES=ASSIGNEE; PLUR=YES; OP=OR			
L9	gps$ and vehicle and ((compar$ with confiden$) same error$)	0	L9
L8	gps$ and vehicle and ((compar$ with confiden$) same (threshold$ with error$))	0	L8
L7	gps$ and vehicle and ((colinear$ or regressi$) same (threshold$ with error$))	0	L7
L6	gps$ and vehicle and (compar$ same (colinear$ or regressi$) same (threshold$ with error$))	0	L6
DB=PGPB; THES=ASSIGNEE; PLUR=YES; OP=OR			
L5	L1 and (chaos$ same compar$)	1	L5
L4	L1 and threshold$.clm.	1	L4
L3	L1 and (error$ same threshold$)	1	L3
L2	L1 and (colinear$ same confiden$)	1	L2
L1	20050090938	1	L1

END OF SEARCH HISTORY

Sat, 18 Aug 2007, 9:44:12 PM EST

Edit an existing query or compose a new query in the Search Query Display.

Search Query Display

10/605768

Select a search number (#) to:

- Add a query to the Search Query Display
- Combine search queries using AND, OR, or NOT
- Delete a search
- Run a search

Recent Search Queries

#1	(compar* <paragraph> ((colinear* <or> regression*) <sentence> confiden*) <paragraph> (threshold* <sentence> error*)) <in> pdfdata
#2	(compar* <and> ((colinear* <or> regression*) <sentence> confiden*) <paragraph> (threshold* <sentence> error*)) <in> pdfdata
#3	(compar* <and> ((colinear* <or> regression*) <sentence> confiden*) <paragraph> (threshold* <sentence> error*)) <in> pdfdata
#4	(compar* <and> ((colinear* <or> regression*) <sentence> confiden*) <paragraph> (threshold* <sentence> error*)) <in> pdfdata
#5	(compar* <and> ((colinear* <or> regressi*) <sentence> confiden*) <paragraph> (threshold* <sentence> error*)) <in> pdfdata
#6	(compar* <and> ((co-linear* <or> regressi*) <sentence> confiden*) <paragraph> (thres-hold* <sentence> error*)) <in> pdfdata
#7	(compar* <and> ((co-linear* <or> regressi*) <sentence> confiden*) <paragraph> (threshold* <sentence> error*)) <in> pdfdata
#8	(compar* <and> ((co-linear* <or> regressi*) <sentence> confiden*) <paragraph> (threshold* <sentence> error*)) <in> pdfdata

Results for **"(compar* <and> ((colinear* <or> regression*) <sentence> confiden*) <paragraph&g..."**

e-mail

Your search matched **1** of **1632036** documents.

A maximum of **100** results are displayed, **25** to a page, sorted by **Relevance** in **Descending** order.

» Search Options

View Session History

New Search

Modify Search

(compar* <and> ((colinear* <or> regression*) <sentence> confiden*) <paragraph> (th Search

Check to search only within this results set

Display Format: Citation Citation & Abstract

» Key

IEEE JNL	IEEE Journal or Magazine
IET JNL	IET Journal or Magazine
IEEE CNF	IEEE Conference Proceeding
IET CNF	IET Conference Proceeding
IEEE STD	IEEE Standard

view selected items Select All Deselect All

1. **Optimization of voiced/Unvoiced decisions in nonstationary noise enviro**
   Kobatake, H.;
   Acoustics, Speech, and Signal Processing [see also IEEE Transactions on Sig
   IEEE Transactions on
   Volume 35, Issue 1, Jan 1987 Page(s):9 - 18
   AbstractPlus | Full Text: PDF(968 KB) **IEEE JNL**
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Optimization of voiced/Unvoiced decisions in nonstationa environments

Kobatake, H.
Tokyo University of Agriculture and Technology, Tokyo, Japan

This paper appears in: **Acoustics, Speech, and Signal Processing [see also IEEE Tra Processing], IEEE Transactions on**
Publication Date: Jan 1987
Volume: 35 , Issue: 1
On page(s): 9 - 18
ISSN: 0096-3518
Posted online: 2003-01-29 10:33:02.0

Abstract
This paper describes a way of optimizing the autocorrelation method of voiced/unvoiced which is heavily degraded by nonstationary ambient noise. Usually a constant threshold i the correlation peak value is compared for voiced/ unvoiced decision. The optimal thresh function of noise characteristics and the signal-to-noise ratio. This paper presents a meth probability density function of correlation peak values from noisy speech and also of estir threshold based on the expected error rate of the voiced/unvoiced decision. The perform method has been tested under various noise characteristics and signal-to-noise ratios. TI the estimated threshold is very close to the true optimal threshold in almost all cases. Th also retains the optimality under slowly time-varying noise conditions, even if no a priori i about noise characteristics or noise level.

Index Terms

Inspec

Controlled Indexing
Not Available

Non-controlled Indexing
Not Available

Author Keywords
Not Available

References

No references available on IEEE Xplore.

Citing Documents

No citing documents available on IEEE Xplore.

Refine Search

Search Results -

Terms	Documents
gps$ and vehicle and ((compar$ with confiden$) same error$)	0

Database:
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EPO Abstracts Database
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Derwent World Patents Index
IBM Technical Disclosure Bulletins

Search: 10/605,768

Refine Search

Recall Text Clear Interrupt

Search History

DATE: Saturday, August 18, 2007 **Purge Queries** Printable Copy
Create Case

Set Name side by side	Query	Hit Count	Set Name result set
	DB=EPAB,JPAB,DWPI,TDBD; THES=ASSIGNEE; PLUR=YES; OP=OR		
L9	gps$ and vehicle and ((compar$ with confiden$) same error$)	0	L9
L8	gps$ and vehicle and ((compar$ with confiden$) same (threshold$ with error$))	0	L8
	gps$ and vehicle and ((colinear$ or regressi$) same		

L7	(threshold$ with error$))	0	L7
L6	gps$ and vehicle and (compar$ same (colinear$ or regressi$) same (threshold$ with error$))	0	L6

DB=PGPB; THES=ASSIGNEE; PLUR=YES; OP=OR

L5	L1 and (chaos$ same compar$)	1	L5
L4	L1 and threshold$.clm.	1	L4
L3	L1 and (error$ same threshold$)	1	L3
L2	L1 and (colinear$ same confiden$)	1	L2
L1	20050090938	1	L1

END OF SEARCH HISTORY

Refine Search

Your wildcard search against 10000 terms has yielded the results below.
Your result set for the last L# is incomplete.
The probable cause is use of unlimited truncation. Revise your search strategy to use limited truncation.

Search Results -

Terms	Documents
L58 and (compar$ same (predict$ with path$) same (desir$ with path$))	1

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US Patents Full-Text Database
US OCR Full-Text Database
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Search History

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Create Case

Set Name side by side	Query	Hit Count	Set Name result set
	DB=PGPB,USPT,USOC,EPAB,JPAB,DWPI,TDBD; THES=ASSIGNEE; PLUR=YES; OP=OR		

L59	L58 and (compar$ same (predict$ with path$) same (desir$ with path$))	1	L59
L58	l54 or l55 or l56 or l57	50	L58
	DB=USPT; THES=ASSIGNEE; PLUR=YES; OP=OR		
L57	(4897642 | 5043736 | 5146231 | 4672382 | 5173709 | 4881080 | 5089816 | 2861264 | 4599620 | 4949089 | 4954833 | 4903212 | 4741245)![PN]	13	L57
L56	("5266958")[PN]	1	L56
	DB=PGPB,USPT,USOC,EPAB,JPAB,DWPI,TDBD; THES=ASSIGNEE; PLUR=YES; OP=OR		
L55	l53	1	L55
	DB=USPT; THES=ASSIGNEE; PLUR=YES; OP=OR		
L54	("5266958")[URPN]	36	L54
	DB=PGPB,USPT,USOC,EPAB,JPAB,DWPI,TDBD; THES=ASSIGNEE; PLUR=YES; OP=OR		
L53	l13 and (compar$ same (predict$ with path$) same (desir$ with path$))	1	L53
L52	L39 and (compar$ same (colinear$ or regressi$) same error$)	0	L52
L51	L39 and (compar$ same (colinear$ or regressi$) same (threshold$ with error$))	0	L51
L50	L39 and (compar$ same confiden$ same (threshold$ with error$))	0	L50
L49	L39 and (compar$ same (confiden$) same (threshold$ with error$))	0	L49
L48	L39 and gps$ and vehicle and (compar$ same (confiden$) same (threshold$ with error$))	0	L48
L47	L39 and gps$ and vehicle and (compar$ same (colinear$ or regressi$) same (threshold$ with error$))	0	L47
L46	L41 and gps$ and vehicle and (compar$ same (colinear$ or regressi$) same (threshold$ with error$))	0	L46
L45	L44 and gps$ and vehicle and (compar$ same (colinear$ or regressi$) same (threshold$ with	0	L45

	error$))		
	DB=USPT; THES=ASSIGNEE; PLUR=YES; OP=OR		
L44	L43 and (compar$ same (driver$ near4 input$))	10	L44
	DB=PGPB,USPT,USOC,EPAB,JPAB,DWPI,TDBD; THES=ASSIGNEE; PLUR=YES; OP=OR		
L43	L42 and inputs	26	L43
L42	L41 and (driver$ near4 input$)	26	L42
L41	L40 and ((automobile or vehicle or car$ or driv$) same input$)	97	L41
L40	L39 and ((701/201 |701/202 |701/208 |701/209 |701/210 |701/211 |701/213).ccls.)	150	L40
L39	L37 or L38	530	L39
L38	((compar$ with (path$ or way$ or route$)) same gps$) and @pd<=20031024	306	L38
L37	((compar$ with (path$ or way$ or route$)) same gps$) and @ad<=20031024	521	L37
	DB=PGPB,USPT,USOC; THES=ASSIGNEE; PLUR=YES; OP=OR		
L36	L35 and @ad<=20031024	26	L36
L35	L34 and ((compar$ with (path$ or way or route)) with (predict$ or forecast$)) and ((calculat$ or desire$ or plan$) with (path$ or way or route))	41	L35
L34	(701/202 |701/208 |701/209 |701/210 |701/213).ccls.	5214	L34
	DB=PGPB,USPT,USOC,EPAB,JPAB,DWPI,TDBD; THES=ASSIGNEE; PLUR=YES; OP=OR		
L33	L32 and ((calculat$ or desire$ or plan$) with (path$ or way or route))	21	L33
L32	L30 and ((compar$ with (path$ or way or route)) with (predict$ or forecast$))	34	L32
L31	L30 and (compar$ with (predict$ or forecast$))	36	L31
L30	L16 and ((701/201 |701/202 |701/208 |701/209 |701/210 |701/211 |701/213).ccls.)	44	L30
L29	L28 and ((701/201 |701/202 |701/208 |701/209 |701/210 |701/211 |701/213).ccls.)	1	L29

L28	L24 or L25	45	L28
L27	L26	9	L27
L26	L25	9	L26
L25	(linear$ with regression$) and (pitch$ and yaw$ and (speed$ or velocit$)) and L11	9	L25
L24	(linear$ with regression$) and (pitch$ and yaw$ and (speed$ or velocit$)) and gps$	45	L24
L23	(linear$ with regression$) and (pitch$ and yaw$ and (speed$ or velocit$)) and L16	1	L23
L22	(linear$ adj regression$) and (pitch$ and yaw$ and (speed$ or velocit$)) and L16	1	L22
L21	(linear$ adj regression$ adj model$) and (pitch$ and yaw$ and (speed$ or velocit$)) and L16	1	L21
L20	L19 and (pitch$ or yaw$ or (speed$ or velocit$))	2	L20
L19	L16 and (linear$ adj regression$ adj model$)	2	L19
L18	L17 and ((speed$ or velocit$) with (vehicle or car$ or automobil$))	7	L18
L17	L16 and ((confide$ or trust$ or reliab$) near2 (degree$ or level$ or scal$))	16	L17
L16	L14 or L15	189	L16
L15	L13 and @pd<=20031024	122	L15
L14	L13 and @ad<=20031024	189	L14
L13	gps$ and ((compar$ with (path$ or way or route)) same (predict$ or forecast$))	287	L13
L12	L10 and @pd<=20031024	5820	L12
L11	L10 and @ad<=20031024	9464	L11
L10	gps$ and ((compar$ with (path$ or way or route)) sme (predict$ or forecast$))	15325	L10

DB=EPAB,JPAB,DWPI,TDBD; THES=ASSIGNEE; PLUR=YES; OP=OR

L9	gps$ and vehicle and ((compar$ with confiden$) same error$)	0	L9
L8	gps$ and vehicle and ((compar$ with confiden$) same (threshold$ with error$))	0	L8

L7	gps$ and vehicle and ((colinear$ or regressi$) same (threshold$ with error$))	0	L7
L6	gps$ and vehicle and (compar$ same (colinear$ or regressi$) same (threshold$ with error$))	0	L6
DB=PGPB; THES=ASSIGNEE; PLUR=YES; OP=OR			
L5	L1 and (chaos$ same compar$)	1	L5
L4	L1 and threshold$.clm.	1	L4
L3	L1 and (error$ same threshold$)	1	L3
L2	L1 and (colinear$ same confiden$)	1	L2
L1	20050090938	1	L1

END OF SEARCH HISTORY